IN THE CLAIMS:

The text of all pending claims (including withdrawn claims) is set forth below. Cancelled and not entered claims are indicated with claim number and status only. The claims as listed below show added text with underlining and deleted text with ~~strikethrough~~. The status of each claim is indicated with one of (ORIGINAL), (CURRENTLY AMENDED), (CANCELLED), (WITHDRAWN), (NEW), (PREVIOUSLY PRESENTED), or (NOT ENTERED).

Please CANCEL claims 1-3 and 6-8, and AMEND claims 4, 5 and 9-15 in accordance with the following:

1. (CANCELLED)

2. (CANCELLED)

3. (CANCELLED)

4. (CURRENTLY AMENDED) A robot with a sensor~~ according to claim 2~~, the robot comprising:

sensor means; and

sensor disposal position changing means to change a disposal position of the sensor means from one position to another, wherein:

a plurality of sensor means disposal positions, including positions at and around a robot arm, are set in advance as positions where the sensor means is disposed;

one of said plurality of sensor means disposal positions is an acting position where the sensor means is used while mounted to a tip end of the robot arm and another is a retreat position where the sensor means retreats from the acting position when not used;

the acting position of the sensor means is near working means mounted to the tip end of the robot arm and the retreat position is on the robot arm; and

~~wherein~~ protecting means ~~for the~~to protect said sensor means ~~is provided~~when said sensor means is in the retreat position.

5. (CURRENTLY AMENDED) A robot with a sensor~~ according to claim 2~~, the robot comprising:

sensor means; and

sensor disposal position changing means to change a disposal position of the sensor

means from one position to another, wherein:

a plurality of sensor means disposal positions, including positions at and around a robot arm, are set in advance as positions where the sensor means is disposed;

one of said plurality of sensor means disposal positions is an acting position where the sensor means is used while mounted to a tip end of the robot arm and another is a retreat position where the sensor means retreats from the acting position when not used;

the acting position of the sensor means is near working means mounted to the tip end of the robot arm and the retreat position is on the robot arm; and

~~wherein~~ cleaning means ~~for the~~to clean said sensor means ~~is provided~~when said sensor means is in the retreat position.

6. (CANCELLED)

7. (CANCELLED)

8. (CANCELLED)

9. (CURENTLY AMENDED) A robot with a sensor ~~according to claim 7~~, the robot comprising:

sensor means; and

sensor disposal position changing means to change a disposal position of the sensor means from one position to another, wherein:

a plurality of sensor means disposal positions are set in advance as positions where the sensor means is disposed;

one of said plurality of sensor means disposal positions is an acting position where the sensor means is used while mounted to a tip end of the robot arm and another is a retreat position where the sensor means retreats from the acting position when not used;

the acting position of the sensor means is near working means mounted to the tip end of the robot arm and the retreat position is on the robot arm; and

~~wherein~~ protecting means ~~for the~~to protect said sensor means ~~is provided~~when said sensor means is in the retreat position.

10. (CURRENTLY AMENDED) A robot with a sensor ~~according to claim 7~~, the robot comprising:

sensor means; and

sensor disposal position changing means to change a disposal position of the sensor means from one position to another, wherein:

a plurality of sensor means disposal positions are set in advance as positions where the sensor means is disposed;

one of said plurality of sensor means disposal positions is an acting position where the sensor means is used while mounted to a tip end of the robot arm and another is a retreat position where the sensor means retreats from the acting position when not used;

the acting position of the sensor means is near working means mounted to the tip end of the robot arm and the retreat position is on the robot arm; and

~~wherein~~ cleaning means ~~for the~~to clean said sensor means ~~is provided~~when said sensor means is in the retreat position.

11. (CURRENTLY AMENDED) A robot with a sensor according to claim ~~14~~4, wherein the sensor means is a visual sensor having a camera for taking a two-dimensional image.

12. (CURRENTLY AMENDED) A robot with a sensor according to claim ~~14~~4, wherein the sensor means is a measuring sensor for carrying out a three-dimensional measurement by using laser light.

13. (CURRENTLY AMENDED) A robot with a sensor according to claim ~~14~~4, wherein the sensor means is a force sensor for outputting a signal according to an external force.

14. (CURRENTLY AMENDED) A robot with a sensor according to claim ~~14~~4, wherein the sensor disposal position changing means is formed of retaining means for retaining the sensor means provided in each ~~the~~ disposal position and stores software including instructions~~in which a setting for controlling~~ to control the operation ~~for~~of handing the sensor means from one of the retaining means to another, which is ~~and~~ carried out by the robot on its own ~~is stored~~.

15. (CURRENTLY AMENDED) A robot with a sensor according to claim ~~14~~4, wherein the sensor disposal position changing means is formed of driving means provided to an arm having a wrist at its tip end to drive the sensor means forward and backward to a working position and a retreat position, working means of the robot being mounted to the wrist.